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		<i>DB=PGPB,USPT,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ</i>	
<input type="checkbox"/>	L22	116 and L21	110
<input type="checkbox"/>	L21	118 and L20	11540
		(700/245,247,248,251,257,258,259,260,261,262,264 or	
<input type="checkbox"/>	L20	318/568.11,568.12,568.13,568.26,568.21,568.25 or 606/1,102,130,139 or 600/117,118,407,126,429,587,595 or 901/1,2,27).ccls.	14418
<input type="checkbox"/>	L19	L18 and L5	1
<input type="checkbox"/>	L18	(robot\$6 or articulat\$3 or automat\$6 or autonomous\$2 or CNC or machine\$2 or mechanical device or mechan\$6 or servomechan\$4)	7486194
		<i>DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ</i>	
<input type="checkbox"/>	L17	115 and L16	0
<input type="checkbox"/>	L16	(backward or reverse or reciprocating) motion\$	67394
		(5572103 4595989 4967127 6438437 4506448 4897586 5724489 5555347 5020001 5243266 5987591 6097169 5313563 5467003 5489758 5582750 5608618 5715388 5773950 6192288 5371836 4433382 4777608 5006999 5495090 6157873 6167328 4403281 4817017 4831316 4853603 4970370 5015821 5276777 5300868 5327057 5412759 5457773 5479078 5671962 5761390 6021361 6019606 6069338 6140788 5239159 4871252 4362977 4348623 4475160).pn.	102
<input type="checkbox"/>	L15		
<input type="checkbox"/>	L14	('6452131' '5961858' '5925268')!.PN.	7
<input type="checkbox"/>	L13	teaching pendant and servo and controllers and laser and sensor and computer and robot	5
<input type="checkbox"/>	L12	teaching console and controllers and laser and sensor and computer and robot	1
<input type="checkbox"/>	L11	teaching console and servo and controllers and laser and sensor and computer and robot	1
		<i>DB=PGPB,USPT,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ</i>	
<input type="checkbox"/>	L10	teaching console and servo and controllers and laser and sensor and computer and robot	1
<input type="checkbox"/>	L9	teaching console and "servo controllers" and laser	1
<input type="checkbox"/>	L8	teaching console and "servo controller #n" and laser	0
<input type="checkbox"/>	L7	servomotors and M1 same M6 and pendant	2
<input type="checkbox"/>	L6	servomotors and M1 same Mn and pendant	1
<input type="checkbox"/>	L5	servomotors and M1 and Mn and pendant	1
<input type="checkbox"/>	L4	servomotors and "M1 to Mn" and pendant	0
<input type="checkbox"/>	L3	sevomotors and M1 and Mn and pendant	0
<input type="checkbox"/>	L2	sevomotors and "m1 to mn"	0
<input type="checkbox"/>	L1	sevomotors and "M1 to Mn"	0

END OF SEARCH HISTORY



Key: IEEE JNL = IEEE Journal or Magazine, IEE JNL = IEE Journal or Magazine, IEEE CNF = IEEE Conference, IEE CNF = IEE Conference, IEEE STD = IEEE Standard

1. **Control of a mobile robot with passive multiple trailers**
Myoungkuk Park; Woojin Chung; Munsang Kim; Jaebok Song;
Robotics and Automation, 2004. Proceedings. ICRA '04. 2004 IEEE International Conference on
Volume 5, 26 April-1 May 2004 Page(s):4369 - 4374 Vol.5
IEEE CNF
2. **Ver-vite: dynamic and experimental analysis for inchwormlike biomimetic robots**
Rincon, D.M.; Sotelo, J.;
Robotics & Automation Magazine, IEEE
Volume 10, Issue 4, Dec. 2003 Page(s):53 - 57
IEEE JNL
3. **A practical path and motion planner for a tractor-trailer robot**
Viale, M.; Tsubochi, T.; Yuta, S.;
Intelligent Robots and Systems, 1997. IROS '97., Proceedings of the 1997 IEEE/RSJ International Conference on
Volume 2, 7-11 Sept. 1997 Page(s):989 - 996 vol.2
IEEE CNF
4. **Towards efficient implementation of quadruped gaits with duty factor of 0.75**
Hugel, V.; Blazevic, P.;
Robotics and Automation, 1999. Proceedings. 1999 IEEE International Conference on
Volume 3, 10-15 May 1999 Page(s):2360 - 2365 vol.3
IEEE CNF
5. **Discontinuous control for exponential stabilization of wheeled mobile robots**
Tayebi, A.; Rachid, A.;
Intelligent Robots and Systems '96, IROS 96, Proceedings of the 1996 IEEE/RSJ International Conference on
Volume 1, 4-8 Nov. 1996 Page(s):60 - 65 vol.1
IEEE CNF
6. **Experimental Research of a Passive Multiple Trailer System for Backward Motion Control**
Myoungkuk Park; Woojin Chung; Munsang Kim;
Robotics and Automation, 2005. ICRA 2005. Proceedings of the 2005 IEEE International Conference on
18-22 April 2005 Page(s):105 - 110
IEEE CNF
7. **Analysis of part motion on a longitudinally vibrating plate**
Reznik, D.; Canny, J.; Goldberg, K.;
Intelligent Robots and Systems, 1997. IROS '97., Proceedings of the 1997 IEEE/RSJ International Conference on
Volume 1, 7-11 Sept. 1997 Page(s):421 - 427 vol.1
IEEE CNF

**8. Path-tracking of a tractor-trailer vehicle along rectilinear and circular paths:
a Lyapunov-based approach**

Astolfi, A.; Bolzern, P.; Locatelli, A.;
Robotics and Automation, IEEE Transactions on
Volume 20, Issue 1, Feb. 2004 Page(s):154 - 160
IEEE JNL

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Key: IEEE JNL = IEEE Journal or Magazine, IEE JNL = IEE Journal or Magazine, IEEE CNF = IEEE Conference, IEE CNF = IEE Conference, IEEE STD = IEEE Standard

1. Miniature robot with micro capillary capturing probe

Aoyama, H.; Hiraiwa, S.; Iwata, F.; Fukaya, J.; Sasaki, A.;
Micro Machine and Human Science, 1995. MHS '95., Proceedings of the Sixth
International Symposium on
4-6 Oct. 1995 Page(s):173 - 178

IEEE CNF

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Reciprocating Motion. Reciprocating motions may be hazardous because, ... of sensors that are employed continually to monitor the **robot's** axes for ...[www.nclabor.com/osha/etta/indguide/ig3.pdf](#) - [Similar pages](#)[Electroactive polymer rotary motors - Patent 6806621](#)IEEE Micro **Robots** and Teleoperators Workshop, Hyannis, ... Repeated actuation of the transducer will produce **reciprocating motion**.**Reciprocating** motion of a ...[www.freepatentsonline.com/6806621.html](#) - 148k - [Cached](#) - [Similar pages](#)[Control apparatus for electric actuator - Patent 7042187](#)In general, when an industrial **robot** of the installation type is used, ... 14 makes **reciprocating motion linearly** when driven by a rotary driving source 12, ...[www.freepatentsonline.com/7042187.html](#) - 36k - [Cached](#) - [Similar pages](#)[motion actuator rod on GlobalSpec](#)**Robot** Automation, Linear Actuators, Motion Controllers & Software**reciprocating motion actuator, reciprocating** to rotary motion, rotary actuator ...[motion-controls.globalspec.com/Industrial-Directory/motion_actuator_rod](#) - 73k - [Cached](#) - [Similar pages](#)**[PDF]** [Friction: experimental determination, modeling and compensation ...](#)

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plot of the desired and actual **robot** motion during a 20. secondhttp://www.google.com/search?hl=en&lr=&q=+robot+and+%22reciprocating+motion*%22

reciprocating motion. This motion. was conducted open loop, there was no error ...

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reciprocating motion of magnetic piston which is. accelerated by solenoids current can push and ... Recently we also succeeded in producing a small **robot** ...

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Class Definition for Class 118 - COATING APPARATUS

... holder for grasping the work and imparting a **reciprocating motion thereto**. ... 901,, **Robots**, subcollection 43 for a programmed **robot** which performs a ...

www.uspto.gov/go/classification/uspc118/defs118.htm - 826k -

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[Paper] DESIGN AND TESTING OF AN ULTRA-HIGH-SPEED CABLE ROBOT

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